

TITLE OF THE INVENTION

REMOTE SYNCHRONIZATION IN PACKET-SWITCHED NETWORKS

BACKGROUND

[0001] The present invention relates to remote node synchronization, and more particularly, to remote node synchronization over a packet-switched network where all intermediary nodes are not necessarily synchronized.

[0002] Because synchronous networks tend to be expensive, packet-switched networks are usually not synchronized meaning that there is no common reference clock in the network. The IEEE 802.3 standard, often referred to as Ethernet, is an example asynchronous network that uses free-running clocks in all nodes. Although asynchronous networks are appropriate for many applications, in other applications, synchronization is important or otherwise desirable.

[0003] One example application where synchronization is important is radio access network (RANs) used in mobile radio communications. Present day, circuit-switched RANs use plesiochronous digital hierarchy (PDH), (e.g. E1), or synchronous digital hierarchy (SDH), (e.g., STM-1), links between RAN nodes. Due to the well-controlled jitter and wander characteristics of these transmission technologies, clock-recovery techniques can be utilized to reach 50 parts-per-billion (ppb) frequency accuracy necessary for the third generation, wideband code-division multiple access (WCDMA) air interface.

[0004] Instead of using circuit-switched communications where synchronization is based on SDH or PDH, it would be desirable to employ packet-switched network technologies for RAN node communications since packet-switched network infrastructures already exist. If that were to occur, there will be intermediary repeaters, switches, and routers (hereafter referred to as intermediary nodes) between the RAN nodes like radio base stations (RBSs), radio network controllers (RNCs), or the like. The intermediary nodes inject delays and uncertainties into the synchronization process

not encountered in circuit-switched networks. Nonetheless, certain applications, such as WCDMA as mentioned above, require frequency-synchronization at a very high accuracy, and may also require absolute time synchronization. The latter is important for several positioning method of cellular terminals, e.g., Global Positioning System (GPS)-assisted positioning. Moreover, clock-recovery techniques can not be used for packet-switched, asynchronous network technologies like Ethernet, Internet Protocol (IP), or Asynchronous Transfer Mode (ATM).

[0005] A solution is needed that generally provides means for remote node synchronization over packet-switched networks between a sending node and a receiving node without requiring synchronization of any intermediary nodes. That solution should also solve specific problems and needs associated with synchronizing RAN nodes that employ packet-switched communications, e.g., very accurate synchronization for both frequency and absolute time.

[0006] Synchronization over packet-switched networks can be achieved using several approaches. One approach is to adjust the receiving node's clock based on the "filling level" of an elastic jitter buffer, as shown in Figure 1. Upper and lower window boundaries are defined around the middle of the jitter buffer. For every n samples, the average position of a buffer pointer is calculated. In normal operation, the average pointer position should be around the middle of the window. If the average pointer position goes above the upper window boundary or below the lower window boundary, the receiving node's clock is corrected to return the average pointer position to the middle of the buffer.

[0007] Drawbacks of this approach include sensitivity to frame/packet loss. If a frame/packet is lost, the buffer decreases. Another drawback is the requirement for timeservers with very accurate periodicity. Few accurate periodicity timeservers which allow ppb accuracy to be reached are available on the market, and they are slow, with a periodicity on the order several seconds.

[0008] Another approach for frequency synchronization over packet-switched networks employs periodic timestamp transmission illustrated in Figure 2. A

Timeserver Q (e.g., an RNC) sends timestamps to a client receiver P (e.g., an RBS) with a predetermined periodicity. The frequency drift and time offset between Q and P are estimated from the timestamp periodicity so the periodicity must be accurate. Drawbacks of this approach are similar to those described for the jitter buffer approach described above including sensitivity to frame/packet loss and timeservers with very accurate periodicity.

[0009] A third approach relies on time differences between the timeserver P and the client Q. Advantages include insensitivity to frame/packet loss and no periodicity requirement. Figure 3 illustrates a one-way timestamp procedure. A timestamp message, e.g., a network time protocol (NTP) message, is sent from the timeserver to the client through a number of intermediary nodes (e.g., switches). When sending the message, the timeserver inserts an absolute local time t_3 in the message. When the client receives the message, it adds the absolute local time t_4 to the message. The differential time $\Delta t_{43} = t_4 - t_3$ can then be calculated and evaluated by the client.

[0010] The differential time, in this case $\Delta t_{43} = t_4 - t_3$, is compared with the absolute local time t_4 in the client. Figure 4 shows multiple differential times Δt_{43} being plotted relative to the absolute local time t_4 . An oscillator frequency drift in the client appears as a drift in the differential time which is shown in Figure 4 as a dashed line. The drift slope ρ (i.e., the slope of the dashed line), corresponds to the client's frequency drift compared to the timeserver. A least-squares algorithm may be used to estimate the differential time drift, but it unfortunately requires a long convergence time.

SUMMARY

[0011] The invention provides for remote synchronization between nodes communication over a packet-switched network using a differential timestamp approach that is immune to packet loss. Only timestamps that arrive at the client are evaluated. A lost timestamp is not accounted for. Intermediary nodes need not be synchronized or modified. Periodicity (cyclic timing) is not required. A fast

convergence time is achieved using a filtering process where a line is fit to multiple differential time values using a minimum delay principle. Frequency synchronization and/or absolute time synchronization between the two nodes may be achieved using one or both of uplink and downlink differential time values and fitting one or both of first and second lines to minimum differential time values.

[0012] A communications system includes a first node with a first oscillator that sends multiple messages over a packet-switched network. The first node includes or associates with each message a first timestamp corresponding to a time when the first node sent that message. A second node having a second oscillator receives each message and includes or associates with that message a second timestamp corresponding to a time when the second node received that message. One of the nodes determines for each message a first time difference between the corresponding first and second timestamps. From multiple first time differences, the one node fits a line to two or more values of the first time differences. The slope ρ of the line relates to a frequency drift between the first and second oscillators. The one node determines from the line a frequency adjustment to synchronize the first and second oscillators. In one embodiment, the frequency adjustment is a factor of $(1 - \rho)$. An absolute timing adjustment may also be made using the line.

[0013] In a decentralized embodiment, the one node may be the second node which adjusts the second oscillator using the frequency adjustment. This approach is also applicable for a broadcast or multicast situation in which multiple second nodes may be synchronized by one first node broadcasting or multicasting synchronization messages. In a centralized embodiment, the one node is the first node which sends a message to the second node that includes the frequency adjustment for adjusting the second oscillator.

[0014] In one example implementation, the first node is a timeserver and the second node is a client node, and the messages are transported over a packet-switched network. In one application among many others, the system is a mobile communications system, the first node may be a radio network controller, and the

second node is a radio base station. Alternatively, the first node may be a radio base station, and the second node is a radio network controller. The messages between the radio base station and the radio network controller are packet-switched.

[0015] For more accurate absolute timing synchronization between the first and second nodes, roundtrip time delay measurements (rather than one-way measurements) may be used. The one-way measurements are made, and then the second node includes or associates with the message a third timestamp corresponding to a time when the second node sends that message back to the first node. The first node includes or associates with each received message a fourth timestamp corresponding to a time when the first node received that message. One of the first and second nodes determines for each received message a first time difference between the corresponding first and second timestamps and a second time difference between the corresponding third and fourth timestamps. From multiple sets of first and second time differences, the one node determines a first minimum time difference line and a second minimum time difference line. From those first and second lines, an accurate absolute time adjustment may be determined to synchronize first and second timers in the first and second nodes, respectively. As a network status check, the one node determines whether the slopes of the first and second lines have approximately the same absolute values and whether one of the first and second slopes is positive and the other is negative.

[0016] Although various methods may be used by the one node to fit multiple sets of time differences to a line, line fitting is preferably based on a minimum delay principle. Taking the roundtrip measurements as an example, the one node fits the first and second lines to the first and second sets of time differences by identifying at least two minimum delay time difference points for each set of delay values/points. In one approach, the two minimum delay points in the set separated by the longest distance are determined. The one node determines an equation of a line that intersects the two minimum delay time difference points.

[0017] A more sophisticated “hybrid” algorithm improves the minimum delay line fitting process by providing more than two minimum delay points from which the line is constructed. A set of delay values is divided into intervals, and a minimum delay point is selected from each interval. Procedures are set forth that determine an optimal number of intervals as well as an optimal number of delay points to be included in each interval.

[0018] Other features, aspects, and advantages of the present invention will become apparent from the following detailed description, taken in conjunction with the accompanying drawings, illustrated by way of example the principles of the invention.

BRIEF DESCRIPTION OF THE DRAWINGS

[0019] FIGURE 1 illustrates a jitter buffer synchronization method;

[0020] FIGURE 2 illustrates frequency synchronization using periodic timestamps;

[0021] FIGURE 3 illustrates sending timestamps;

[0022] FIGURE 4 illustrates a drift of differential times estimated by fitting a line to the differential time values;

[0023] FIGURE 5 is function block diagram to describe synchronization procedures between a timeserver node and a client node;

[0024] FIGURE 6 is a graph showing a typical delay distribution of a group of Ethernet message between the timeserver and client;

[0025] FIGURES 7A and 7B show the principle of fitting a line to a minimum time for uplink and downlink differential time sets;

[0026] FIGURE 8 is a flowchart diagram illustrating example frequency synchronization principles;

[0027] FIGURE 9 is flowchart diagram illustrating example absolute timing synchronization principles;

[0028] FIGURE 10 shows a line for the downlink fitted to two minimum delay points;

[0029] FIGURE 11 shows the principle of locating two minimum time values for use in minimum time line fitting;

[0030] FIGURE 12 illustrates a principle of a curve fitting algorithm;

[0031] FIGURE 13 illustrates a principle of an optimized hybrid curve fitting algorithm;

[0032] FIGURE 14 is a curve illustrating a minimum in the variance of the curve fit, corresponding to an optimum number of timestamps in each interval; and

[0033] FIGURE 15 is a graph illustrating convergence times of different line fitting algorithms.

DETAILED DESCRIPTION

[0034] The following description, for purposes of explanation and not limitation, sets forth specific details, such as particular components, electronic circuitry, techniques, etc., in order to provide an understanding of the present invention. But it will be apparent to one skilled in the art that the present invention may be practiced in other embodiments that depart from these specific details. In other instances, detailed descriptions of well-known methods, devices, and techniques, etc., are omitted so as not to obscure the description with unnecessary detail. Individual function blocks are shown in one or more figures. Those skilled in the art will appreciate that functions may be implemented using discrete components or multi-function hardware. Processing functions may be implemented using a programmed microprocessor or general-purpose computer, using an application specific integrated circuit (ASIC), and/or using one or more digital signal processors (DSPs).

[0035] Figure 5 shows an example communications system 10 including a timeserver node (Q) 12 and a client node (P) 16 coupled together via a packet-switched network 14. In one non-limiting example application to a radio access network (RAN), the timeserver 12 may be a radio network controller (RNC), the packet-switched network may be an Ethernet, an IP network, or an ATM network, and the client may be a radio base station (RBS). The packet-switched network 14 includes one or more

intermediary switching and repeater nodes. The timeserver and the client should be synchronized. In different, non-limiting embodiments, they are frequency synchronized, absolute-time synchronized, or both.

[0036] The timeserver 12 includes a processor 18, an frequency oscillator 20, an absolute time timer 22, a buffer 24 for storing data packets to be sent and received, and a transceiver 26 for sending and receiving data packets. The function blocks 18-26 communicate over a bus 28. The client 16 includes a processor 30, an frequency oscillator 32, an absolute time timer 34, a buffer 36 for storing data packets to be sent and received, and a transceiver 38 for sending and receiving data packets. The function blocks 30-38 communicate over a bus 40. A timestamp message M, such as an NTP message, is generated by one of the processors, stored in its buffer, and transmitted via its transceiver over the packet-switched network 14.

[0037] For purposes of illustration, a preferred example synchronization embodiment is described using roundtrip measurements. Absolute time synchronization is usually better achieved using roundtrip measurements--frequency synchronization only requires one-way measurements. But roundtrip measurements may also be desirable for frequency synchronization since they permit the frequency drift to be measured independently in two ways, thereby limiting negative congestion effects in either the uplink or downlink direction.

[0038] The client 16 sends a timestamp message M, e.g., a procedure-class NTP message, to the timeserver 12 which echoes the message M back to the client 16. When sending the message, the client 16 inserts a local time (absolute time) t_1 output by its timer 34 in the message M (①). The timeserver 12 receives the message M and adds the local time t_2 output by its timer 22 to the message (②). The timeserver 12 sends the message M back to the client 16 at time t_3 (③) and inserts the local time t_3 into the message M. The client 16 receives the message M at local time t_4 (④) and inserts t_4 into the message M.

[0039] This synchronization procedure is decentralized. Each client-originated message M includes all four timestamps. The timeserver 12 therefore need not monitor

every client for synchronization. Instead, the timeserver 12 simply waits to receive a timestamp message from each client. A centralized approach may also be used where the timeserver 12 sends the timestamp messages to poll each client 16. But the centralized approach requires sending an additional adjustment message from the timeserver to the client. Both decentralized and centralized approaches may also be used with one-way differential time measurements—either uplink or downlink directions. One-way differential time measurements in the downlink direction are applicable for broadcast or multicast synchronization in which a timeserver simultaneously sends timestamp messages to a group of clients.

[0040] Synchronization requires compensation for a message delay between the timeserver 12 and the client 16. The delay includes a propagation delay (travel time) and a processing delay in the timeserver, the client, and any intermediary nodes. But that message delay changes because the propagation delay and/or processing delay changes. For example, propagation times vary because the messages travel different paths through the packet-switched network. The processing delays vary because of changing queuing delays in the intermediary nodes, timeserver, and/or client.

Differential timestamps allow both delay sources to be accounted for.

[0041] Figure 4 (already described above) shows the numerous different delay values (x's) in sending different messages from the timeserver to the client. The message delay has a probability density function (PDF). It is preferable to evaluate a large number of timestamp messages during a short time period because of queuing effects in the intermediary nodes. A snapshot of this distribution can be obtained by using a large number of messages.

[0042] Rather than using an average delay value determined from all of the measured delays, synchronization in the present invention is determined based on a minimum delay. The minimum delay time that a timestamp message may experience is well defined by the part of the switch processing that is essentially constant, e.g., shortest intermediary switch path, minimum processing time for such functions as address lookup, prioritization, error-detecting codes, etc. The minimum delay time is

plainly indicated by the waveform peak in Fig. 6. The maximum time or the average time, on the other hand, is less well defined since a timestamp may be subjected to variable delay amounts due to different amounts of, e.g., queuing in each intermediary node.

[0043] The framework for both frequency and absolute time synchronization using the minimum delay principle is now explained. As explained for the example shown in Fig. 5, the client sends timestamp messages M (e.g., NTP messages). In the roundtrip example, each message M includes four timestamps t_1 , t_2 , t_3 and t_4 when it returns to the client. There is a varying difference or “drift” in the client’s oscillator 32 relative to the timeserver’s oscillator 20. That drift ρ is illustrated in Fig. 4.

[0044] Let $t_{\min} + \alpha$ and $t_{\min} + \beta$, $\alpha \geq 0$, $\beta \geq 0$, be the real time delays experienced by the uplink and downlink, respectively. t_{\min} is the minimum time P to Q or Q to P (symmetry is assumed between the up and down links). The variables α and β represent the changing delay in the network (e.g., queuing). Assume the local time at P and Q can be expressed in terms of a time difference term Δt_{PQ} :

$$t_P = t_Q + \Delta t_{PQ} \quad (1)$$

Assume also that Δt_{PQ} includes an offset term t_{offset} (the offset between the absolute times generated by the timeserver timer 22 and the client timer 34) and the frequency drift term ρ :

$$\Delta t_{PQ} \equiv \rho \cdot t_P + t_{\text{offset}} \quad (2)$$

Δt_{PQ} may take both positive and negative values.

[0045] Two time differences in terms of t_1 , t_2 , t_3 and t_4 can be obtained from a roundtrip timestamp:

$$\Delta t_{43} \equiv (t_4 - t_3) \quad (3)$$

$$\Delta t_{21} \equiv (t_2 - t_1) \quad (4)$$

[0046] It is possible to express t_4 and t_2 in terms of t_{\min} , α , β , and Δt_{PQ} :

$$\begin{aligned} t_4 = t_P = t_Q + \Delta t_{PQ} &= t_3 + t_{\min} + \beta + \Delta t_{PQ} \\ \Rightarrow \Delta t_{43} &= t_{\min} + \beta + (\rho \cdot t_4 + t_{\text{offset}}) \end{aligned} \quad (5)$$

[0047] Likewise, we obtain an expression for t_2 :

$$t_2 = t_Q = t_P - \Delta t_{PQ} = t_1 + t_{min} + \alpha - \Delta t_{PQ}$$

where

$$\Delta t_{PQ} = \rho \cdot t_P + t_{offset} = \rho \cdot (t_1 + t_{min} + \alpha) + t_{offset}$$

$$\Rightarrow \Delta t_{21} = (1-\rho)(t_{min} + \alpha) - (\rho \cdot t_1 + t_{offset}) \quad (6)$$

[0048] Consider the minimum values of Δt_{21} and Δt_{43} when the messages do not experience any variable delay ($\alpha, \beta = 0$):

$$\Delta t_{21, min} = \Delta t_{21}(\alpha=0) = (1-\rho) t_{min} - \rho \cdot t_1 - t_{offset} \quad (7)$$

$$\Delta t_{43, min} = \Delta t_{43}(\beta=0) = t_{min} + (\rho \cdot t_4 + t_{offset}) \quad (8)$$

[0049] Fig. 7A shows a plot of Δt_{21} vs. t_1 according to Eq.(7) with a straight line fit to minimum delay times. The line has a slope $-\rho$ corresponding to the frequency oscillator drift and an intercept with the y-axis of $(1-\rho) t_{min} - t_{offset}$. Similarly, Eq. (8) suggests that minimum delay values in a plot of Δt_{43} vs. t_4 values shown in Fig. 8B may be fit by a straight line with slope ρ and with a y-axis intercept of $t_{min} + t_{offset}$. By comparing each minimum delay line with the well-known equation for a straight line, $y = kx + m$, we can identify from the fitted line its slope k and its y-axis intercept m :

$$k_{21} = -\rho \quad (9)$$

$$m_{21} = (1-\rho) t_{min} - t_{offset} \quad (10)$$

$$k_{43} = \rho \quad (11)$$

$$m_{43} = t_{min} + t_{offset} \quad (12)$$

[0050] The magnitudes of the uplink and downlink slopes k_{43} and $-k_{21}$ should approximately be the same to assure the significance and accuracy of the result. If $|k_{43} + k_{21}| > \epsilon$, where ϵ is a threshold parameter, the measurement should be discarded. The reason for this is likely to be congestion in the network.

[0051] Equations (10) and (12) give

$$m_{43} - m_{21} = \rho t_{min} + 2t_{offset} \approx 2t_{offset} \quad (13)$$

The simplification in Eq. (13) introduces an error in t_{offset} . Since the frequency drift is typically $\sim 10^{-8}$ and $t_{min} \sim 10^{-3}$ s, this error should be much smaller than one nanosecond,

which is acceptable in most cases. Thus, we obtain an expression for t_{offset} -the offset between the absolute times generated by the timeserver timer 22 and the client timer 34:

$$t_{\text{offset}} = (m_{43} - m_{21})/2 \quad (14)$$

The absolute time of the timer 34 for client (P) 16 can be adjusted by the processor 30 to synchronize the two timers 22 and 34 according to:

$$t_{P, \text{adjusted}} = t_Q = \{(1)\} = t_P - \Delta t_{PQ} = \{(2)\} = t_P(1 - \rho) - t_{\text{offset}} \quad (15)$$

The value for t_{offset} is known from Eq. (14) because the uplink and downlink fitted-line y-axis intercepts, m_{43} and m_{21} , are known, and the magnitude of the slope ρ is also known.

[0052] From Eqs. (1) and (2), one obtains a relation between the oscillator frequencies of the timeserver (Q) 12 and the client (P) 16:

$$f_Q = (1 - \rho)f_P \quad (16)$$

The frequency adjustment to synchronize the client P oscillator 32 to the frequency f_Q of the timeserver Q oscillator 20 can be written as:

$$f_{P, \text{adjusted}} = f_Q = (1 - \rho)f_P \quad (17)$$

The processor 30 may, for example, send the frequency adjustment value, $f_{P, \text{adjusted}}$, to a phase-locked loop which then adjusts the oscillator 32.

[0053] Frequency adjustments and/or absolute time adjustments may also be determined using only one-way delay measurements. Consider for example one-way delay measurements including only t_3 and t_4 values. Fig. 7B shows Δt_{43} plotted vs. t_4 . If we fit a straight line to the minimum delay values of Δt_{43} , Eq. (8) can be used to extract $t_{\text{min}} + t_{\text{offset}}$ and ρ . But t_{min} and t_{offset} cannot be separated in the one-way case because there is only one line and three unknowns. But t_{min} can be estimated to some extent with knowledge about intermediary node performance, media delay, etc., so that Eq. (15) may be used to determine an absolute time adjustment for client timer. Still, the absolute time accuracy with only the one-way delay measurements is not as accurate as for the round-trip delay. The frequency adjustment accuracy with one-way delay measurements, however, is the same as for round trip delay measurements

because the line slope ρ is known from the one-way delay line, and Eq. (17) may be solved once the line slope ρ is known.

[0054] Reference is made to example general procedures set forth in a frequency synchronization flowchart in Fig. 8. These procedures assume one-way delay measurements, but roundtrip measurements may be used if desired. A first node N1 sends messages M to a second node N2, with each message M including a first timestamp TS1 corresponding to when the message was sent (step S1). The node N2 adds a second timestamp TS2 when each message M is received (step S2). A time difference Δt_{21} is determined (TS2-TS1) for each message (step S3). From multiple Δt_{21} 's, a line is fit to two or more Δt_{21} values from the set of multiple Δt_{21} 's (step S4). A frequency adjustment is determined from a characteristic of the minimum delay fitted line and used to synchronize the oscillators at nodes N1 and N2 (step S5). In the non-limiting example set forth earlier, the line characteristic is the slope of the line, which is related to frequency drift between the oscillators at nodes N1 and N2, and the frequency adjustment is a factor of 1 minus the slope.

[0055] Reference is made to example general procedures set forth in an absolute timing synchronization flowchart in Fig. 9. These procedures assume roundtrip delay measurements, but one-way measurements may be used as described above. The procedures in Figs. 8 and 9 may be used together or alone or with other procedures.

[0056] A first node N1 sends messages M to a second node N2 with each message M including a first timestamp TS1 corresponding to when the message was sent (step S1). The node N2 adds a second timestamp TS2 when each message M is received and a third timestamp TS3 when the message is sent back (step S2). The node N1 adds a fourth timestamp TS4 when the message M is received (step S3). A first time difference Δt_{21} is determined (TS2-TS1) for each message (step S4). A second time difference Δt_{43} is determined (TS4-TS3) for each message (step S5). From multiple sets of Δt_{21} 's and Δt_{43} 's, a first line is fit to two or more Δt_{21} values from the set of multiple Δt_{21} 's, and a second line is fit to two or more Δt_{43} values from the set of multiple Δt_{43} 's (step S6). From the first and second lines, determine a frequency

adjustment to synchronize oscillators in N1 and N2 and/or a time adjustment to synchronize the first and second timers in N1 and N2 (step S7).

[0057] There are many ways in which lines may be fit to the time delay values. One example technique is to use the well-known least squares algorithm. But the least squares algorithm has a relatively slow convergence time, particularly when a high degree of synchronization is required. Other delay line fitting algorithms that have a faster convergence time are desirable. Two such algorithms will be described: a minimum delay algorithm and a hybrid algorithm.

[0058] The minimum delay algorithm aims to fit a straight line to the minimum delay peak like that shown in Fig. 7. In general, if a straight line were positioned on a curve, the most likely scenario is to have two contact points as illustrated in Fig. 10 and Fig. 11. The idea behind the minimum delay algorithm is to identify these contact points and fit a straight line to these points as shown in Figs. 10 and 11. Ideally, those two points are a significant distance apart.

[0059] The following procedures illustrated conceptually in Fig. 12 describe how to fit Equations (7) and (8) to minimum message delay values or “points.”

1. Calculate multiple slopes, k , from the first Δt data point in the dataset (i.e., “1” in Fig. 12) to all other data points and choose the slope with the minimum value:

$$k_{min1} = \min[(\Delta t_i - \Delta t_1)/(t_i - t_1)], i = 2 \text{ to number of data points}$$

2. From the first data point (1) to the data point (A) which corresponds to k_{min1} , calculate the distance l_1 from the first data point (1) to the new data point (A):

$$l_1^2 = (\Delta t_A - \Delta t_1)^2 + (t_A - t_1)^2$$

3. Calculate slopes from point A to all remaining experimental message delay data points and choose the minimum slope:

$$k_{minA} = \min [(\Delta t_i - \Delta t_A)/(t_i - t_A)], i = A+1 \text{ to the number of data points}$$

4. From (A) to the message delay data point (B), which corresponds to $k_{\min A}$, calculate the distance l_A from the data point (A) to the new data point (B):

$$l_A^2 = (\Delta t_B - \Delta t_A)^2 + (t_B - t_A)^2$$

5. If $l_A^2 > l_I^2$, then $k_{\min A}$ is the best approximation; otherwise, $k_{\min I}$ is the best approximation so far.
6. From data point (B), repeat steps 3 to 6 until all data points in the set have been evaluated.

[0060] In essence, the minimum delay algorithm determines the two minimum delay values that have the longest distance between them. The line is then fitted to intersect those two points. This algorithm is well-suited for evaluating statistical distributions like the one depicted in Fig. 6. In contrast, least-squares algorithms essentially assume Gaussian (symmetrical) distributions and do not apply any filtering to discard outliers in the data set.

[0061] A drawback of the minimum delay algorithm is that its accuracy is only as good as the two selected minimum delay points. Better accuracy may be achieved if more than two minimum delay points are used, e.g., by means of minimum delay procedures that employ different weights. Instead of only two contact points, a weighted average of $k_{\min, i}$ can be used weighted with l_i , l_i^2 or l_i^4 for example:

$$\rho = \frac{\sum_i k_{\min, i} \cdot l_i}{\sum_i l_i} \quad (18)$$

$$\rho = \frac{\sum_i k_{\min, i} \cdot l_i^2}{\sum_i l_i^2} \quad (19)$$

$$\rho = \frac{\sum_i k_{\min, i} \cdot l_i^4}{\sum_i l_i^4} \quad (20)$$

[0062] A second and preferred line-fitting algorithm that also provides better resilience to individual errors in the data points is a combination of the minimum delay algorithm and the least squares algorithm called the “hybrid” algorithm. The hybrid algorithm divides the integration time into a number of intervals and fits a line to the minimum delay value in each interval as depicted in Fig. 13. More intervals mean more data points for the fitting process, which limits the impact of errors in one or more data points on the final result.

[0063] Although any number of intervals may be used, it is preferable to determine an optimal number of timestamp delay values to be included in each interval. If the intervals include too few timestamps, the minimum delay value in each interval will not be an accurate minimum value. On the other hand, if too many timestamps are included, the minimum value will not be accurate because the effect of the drift (the slope) will dominate. In other words, the minimum delay values will probably be found in the beginning of an interval (in case of a positive slope) or towards the end of the interval for a negative slope if too many timestamps are included. This artifact introduces an error that can be controlled by limiting the number of timestamps.

[0064] An analytical expression for the optimal number of timestamps is set forth below. As seen from Eq. (30), the optimal number of timestamps depends on the number and periodicity of the timestamps, the frequency drift, and the magnitude of packet jitter. In order to optimize the number of timestamps, we try to find a minimum variance of the least squares slope σ_b^2 which can be expressed as

$$\sigma_b^2 = S/\Delta \quad (21)$$

where

$$\Delta = S \cdot S_{xx} - (S_x)^2 \quad (22)$$

[0065]

$$\begin{aligned} S &= \sum_{i=1}^N \frac{1}{\sigma_i^2} \\ S_x &= \sum_{i=1}^N \frac{x_i}{\sigma_i^2} \\ S_{xx} &= \sum_{i=1}^N \frac{x_i^2}{\sigma_i^2} \end{aligned} \quad (23)$$

where σ_i^2 is the variance for each delay value or point, and N is the number of delay points used for the fitting, i.e., the number of intervals such as shown in Fig. 13. assume the following:

- There are n data points available in total.
- There are m data points in each interval and is the parameter to which σ_b should be optimized.

This gives:
$$N = n/m \quad (24)$$

- x_i is assumed to be rather periodical, i.e., timestamps are sent more or less periodically.
- t_j is this packet jitter and T is the total experimental time

[0066] Using the above, we may write

$$x_i = i \cdot (T/n) \cdot m \quad (25)$$

[0067] Let us now make two assumptions regarding σ_i : It is the same for all delay points (σ_x), and it is decreasing with the number of delay points in the interval:

$$\sigma_i = \sigma_x = t_j / (c \cdot m) \quad (26)$$

where c is a constant. $c=1$ corresponds to a uniform jitter PDF, whereas $c > 1$ suggests that more timestamps have smaller jitter, as shown in Fig. 7.

[0068] The effect of drift on the standard deviation may be approximated as $1/2 \cdot \rho \cdot (m/n) \cdot T$, which results in:

$$\sigma_i = \sigma_x = t_j / (c \cdot m) + 1/2 \cdot \rho \cdot (m/n) \cdot T \quad (27)$$

Using Eqs. (21)-(27) together with the two sums

$$\sum_{i=1}^N i = \frac{N(N+1)}{2}, \quad \sum_{i=1}^N i^2 = \frac{N(N+1)(2N+1)}{6} \quad (28)$$

we obtain

$$\sigma_b^2 = \sigma_x^2 \cdot (N/T^2) \cdot 12/(N^2-1) \quad (29)$$

[0069] Using Eqs. (24), (27), (29) and minimizing σ_b^2 with respect to m by taking the derivative $d\sigma_b^2/dm = 0$, one obtains an expression for the optimum number of data points in each interval m :

$$m_{optimal} = \sqrt{\frac{3}{2B} \left[(Bn^2 + 1) - \sqrt{(Bn^2 + 1)^2 - \frac{4}{9} Bn^2} \right]} \quad (30)$$

where $B = 1/2 \cdot c \cdot \rho \cdot t_{av} / t_j$ (31)

and $t_{av} = T/n$ (32)

t_{av} is the average time between timestamps. Thus, for a given set of n delay points, a known overall time T and known constant c , an estimated packet jitter t_j , the optimal number of timestamps $m_{optimal}$ may be calculated using Eqs. (30)-(32).

[0070] The optimal number of timestamps depends on several factors including drift, jitter, time between timestamps, and number of timestamps. Fig. 14 shows σ_b^2 versus m/n for the case of 40 timestamps, 30 ms jitter, 32 s between timestamps, and 20 ppb drift. The optimum number of timestamps in each interval is approximately 12%, corresponding to 4 timestamps in each interval.

[0071] Fig. 15 shows simulated convergence abilities of various line fitting algorithms versus number of timestamps (or seconds--timestamps are sent every second in this case). The dotted line corresponds to a least-squares algorithm. The thick line corresponds to the minimum delay algorithm, and the thin line corresponds to the hybrid optimal algorithm. Even after 80 timestamps, the least-squares algorithm does not reach a 30 ppb synchronization window. The minimum delay and hybrid optimal algorithms are both much faster, reaching a 30 ppb window within 20 to 30 timestamps. This kind of convergence speed is important for certain synchronization applications. One example is cold start, RBS frequency synchronization which needs to be achieved in approximately 5 to 10 minutes.

[0072] Synchronization in accordance with various features of the invention provides many benefits. Both frequency and absolute time synchronization may be achieved. The packet-switched network intermediate nodes need not be changed. When comparing equal amount of timestamp traffic, synchronization is achieved much

faster compared to other synchronization algorithms. Timestamp periodicity is not required which facilitates increased timestamp traffic thereby speeding up the synchronization process even further. It is possible to reach 50 ppb accuracy within a few minutes with this method making it possible to cold start an RBS using this synchronization scheme. Packet loss is not a problem, and a standard master-client configuration is readily supported, as well as broadcast/multicast configurations. The preferred use is in a decentralized configuration, but the synchronization procedure can also be used in centralized configurations such as NodeSync over the Iub interface in a UMTS type communications network. Further, the roundtrip embodiment is resilient to network congestion effects since the frequency drift can be estimated in two independent ways so that artifacts can be easily sorted out. The invention may be applied to any packet-switched, asynchronous network, non-limiting examples being Ethernet, ATM, IP, etc.

[0073] While the invention has been described in connection with what is presently considered to be the most practical and preferred embodiments, the invention is not limited to the disclosed embodiments. Rather the invention covers various modifications and equivalent arrangements included within the scope of the appended claims.